# Enhancement of Dexterity in Robotic Grasping Referring to Characteristics of Human Grasping

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- Enhancement of dexterity and agility in concurrent robotic grasping and object manipulation based on the *Sensory-Feedback*

- Two proposed methods referring to characteristics of human grasping
    1. Role-sharing joint control referring to functional characteristics
    2. Modification of finger-tip radius referring to morphological characteristics

- Validation of the proposed methods based on computer simulations

- Analysis by using the *Dexterity Index*
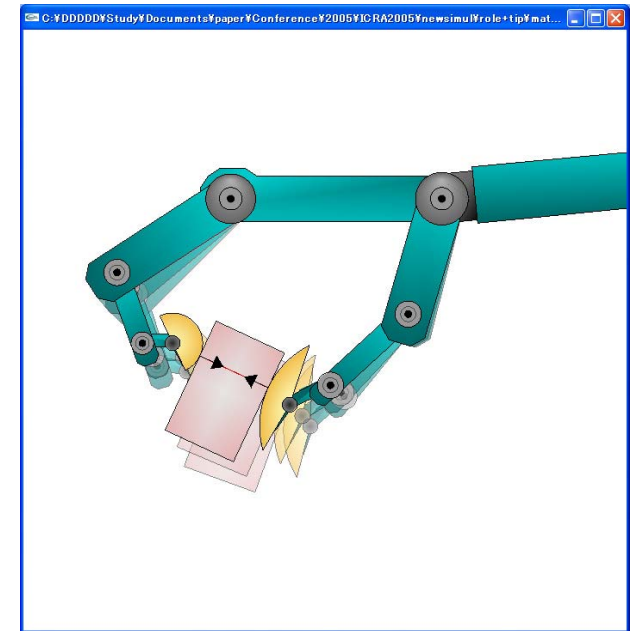
Robotic grasping on the basis of pad-opposition of thumb and index finger